

ABSTRACT OF THE DISCLOSURE

An articulated finger unit has a two-jointed structure comprising a joint portion on a finger base side, a finger base portion, a joint portion on a fingertip side, and a fingertip portion; the
5 joint portion on the finger base side has a drive-side bevel gear fixed to a rotational output shaft of an actuator, a driven-side bevel gear coaxially fixed to a joint portion that is perpendicular to the rotational output shaft, and a connecting member wherein an annular boss is fixed to the driven-side bevel
10 gear and wherein a tip portion extends in a fork shape; and a cover on the finger base side is connected to the connecting member. A rotation of the rotational output shaft is converted to rotational movement of the joint shaft by way of a pair of bevel gears, and the connecting member fixed to the joint shaft
15 turns right and left at an angle of 90° or more about the joint shaft. The finger unit suitable for use in a robot hand that moves at high speed and with precision can be realized.